

*Pub. E10 D6 compl.*  
rejected until the old one is fully completed, also servo calculations compensate time normalization based on the overrun information -- in effect, when overrun occurs, it is as though the clock interval has been doubled in duration.

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✓ Please replace the paragraph starting on page 21, line 15 with the following:

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*D7*  
The force contributions to the various axes are appropriately scaled and applied to a running sum of contributions (which are summed across multiple control function calls). When the control/command function lists are completed, the resulting final set of forces (or torques) become the values set into the output digital to analog interfaces.

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✓ Please replace the paragraph starting on page 22, line 29 with the following:

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*Pub. E12 D8*  
For cases where  $D$  is larger than  $R_{max}$ , the force contribution,  $F_{in}$  and  $F_{out}$ , are  $[0,0]$ . For cases where  $D$  is less than  $R$ ,  $F_{out}$  is zero and  $F_{in}$  is computed as a force directed toward the center,  $X_c, Y_c$ , from the current joint coordinates,  $X, Y$ . This computation is as follows:

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IN THE CLAIMS:

Claims 19-45 are pending. Claims 30-31 are amended. Claims 35-45 are allowed. A marked up copy of all amended claims are in Appendix B. A clean copy of all pending claims are in Appendix C.